

(NASA-CP-151014) TWO-IMU FDI PERFORMANCE OF
THE SEQUENTIAL PROBABILITY RATIO TEST DURING
SHUTTLE ENTRY (McDONNELL-Douglas Technical
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MCDONNELL DOUGLAS TECHNICAL SERVICES CO.
HOUSTON ASTRONAUTICS DIVISION

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SPACE SHUTTLE ENGINEERING AND OPERATIONS SUPPORT

DESIGN NOTE NO. D0410-008

TWO-IMU FDI PERFORMANCE OF THE SEQUENTIAL
PROBABILITY RATIO TEST DURING SHUTTLE ENTRY

MISSION PLANNING, MISSION ANALYSIS AND SOFTWARE FORMULATION

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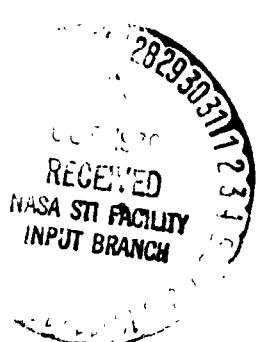
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1.0 SUMMARY

This design note presents 2-IMU FDI performance data for the sequential probability ratio test (SPRT) during shuttle entry. Also included are current modelling constants and failure thresholds for the full mission 3B entry through landing trajectory. FDI results are presented in a "raw data" tabular format in order to furnish the reader with as much data tracking test detection and isolation performance data as is possible, with a minimal amount of data processing. Minimum 100% detection/isolation failure levels and a discussion of the effects of failure direction are presented. Finally, a limited comparison of failures introduced at trajectory initiation shows that the SPRT algorithm performs slightly worse than the data tracking test (Reference 1).

2.0 INTRODUCTION

Last September the SPRT algorithm was baselined at the Level B OFT Entry SDR to perform the onboard 2 and 3 IMU FDI testing with skewed IMU's. In order to both develop and verify the method, a subroutine incorporating the 2-IMU SPRT was added to the IMUFDI triple string IMU simulation program on the JSC Univac 1110. This report contains an evaluation of the present SPRT formulation (Reference 2) in detecting and identifying soft IMU failures.

3.0 DISCUSSION

The 2-IMU SPRT performance data presented in section 4.0 were generated by the IMUFDI program, version 18.C, interfaced with the 2-IMU SPRT subroutine, as described in Reference 2. The following paragraphs contain error modelling data, guidelines, and other

constants specifying the exact conditions under which the enclosed failure test case results were generated.

3.1 Guidelines

- Reference Mission 3B entry
- Simulation begins at entry interface (400 Kft.), and ends at touchdown, 1945 sec. after entry interface
- Only IMU #1 and IMU #2 are ON; IMU #3 is downmoded throughout all test cases
- All failures are introduced into IMU #1 at time t=0 (400 Kft.)
- First detection/isolation tests are performed at time t=10 sec., subsequent tests are performed every 5 sec. thereafter
- Each failure case is tested through 30 Monte Carlo cycles
- The 11° nav base pitch is modeled
- The Kearfott IMU gimbal sequence is used (ZYX-inner middle outer)

The following limitations of the IMUFDI program should be mentioned:

- All IMU's are assumed collocated.
- No tangential or centripetal forces are modeled.
- A 3 gimballed IMU error model is used, error in the 4th (inner roll) gimbal is unmodeled.
- This is an open loop simulation

3.2 Filter Constants

The first order whitening filter is characterized by the following constants:

Autocorrelation time

$$\tau_{GYRO} \approx 120 \text{ sec.}$$

$$\tau_{ACCL} = 120 \text{ sec.}$$

Gains

$$K_{GYRO} = .54$$

$$K_{ACCL} = .084$$

3.3 Base Failure Thresholds

The base failure thresholds are plotted in Figures 1 and 2, together with the 100 Monte Carlo cycle envelopes of nominal data before filtering. The gyro threshold is a 3rd order polynomial function of time, specified by the following coefficients:

$$TGYRO_0 = 3.7 \quad . \quad E-4$$

$$TGYRO_1 = 3.4967 \quad E-6$$

$$TGYRO_2 = -1.1786 \quad E-10$$

$$TGYRO_3 = -5.8263 \quad E-13$$

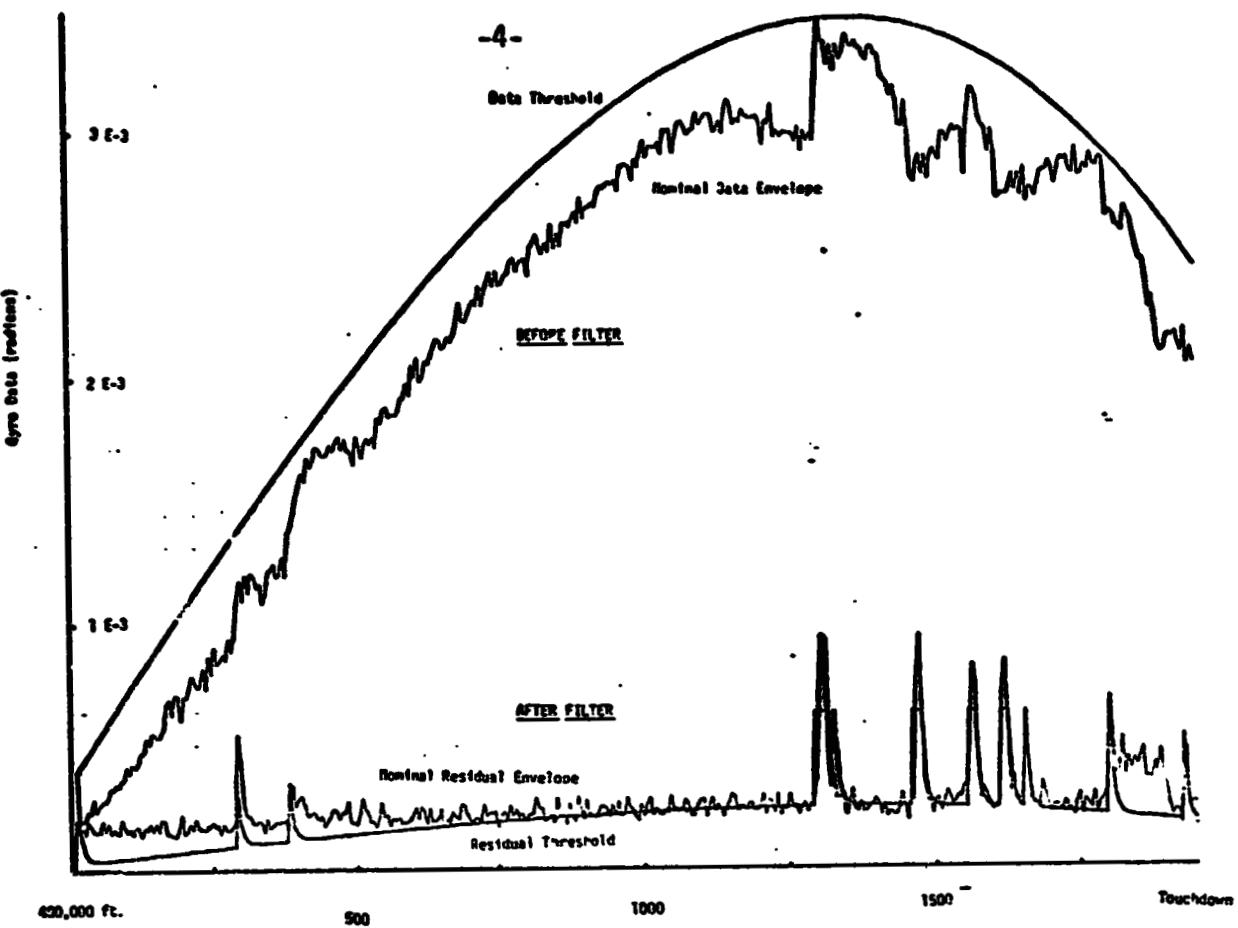


Figure 1. Total Relative Misalignments

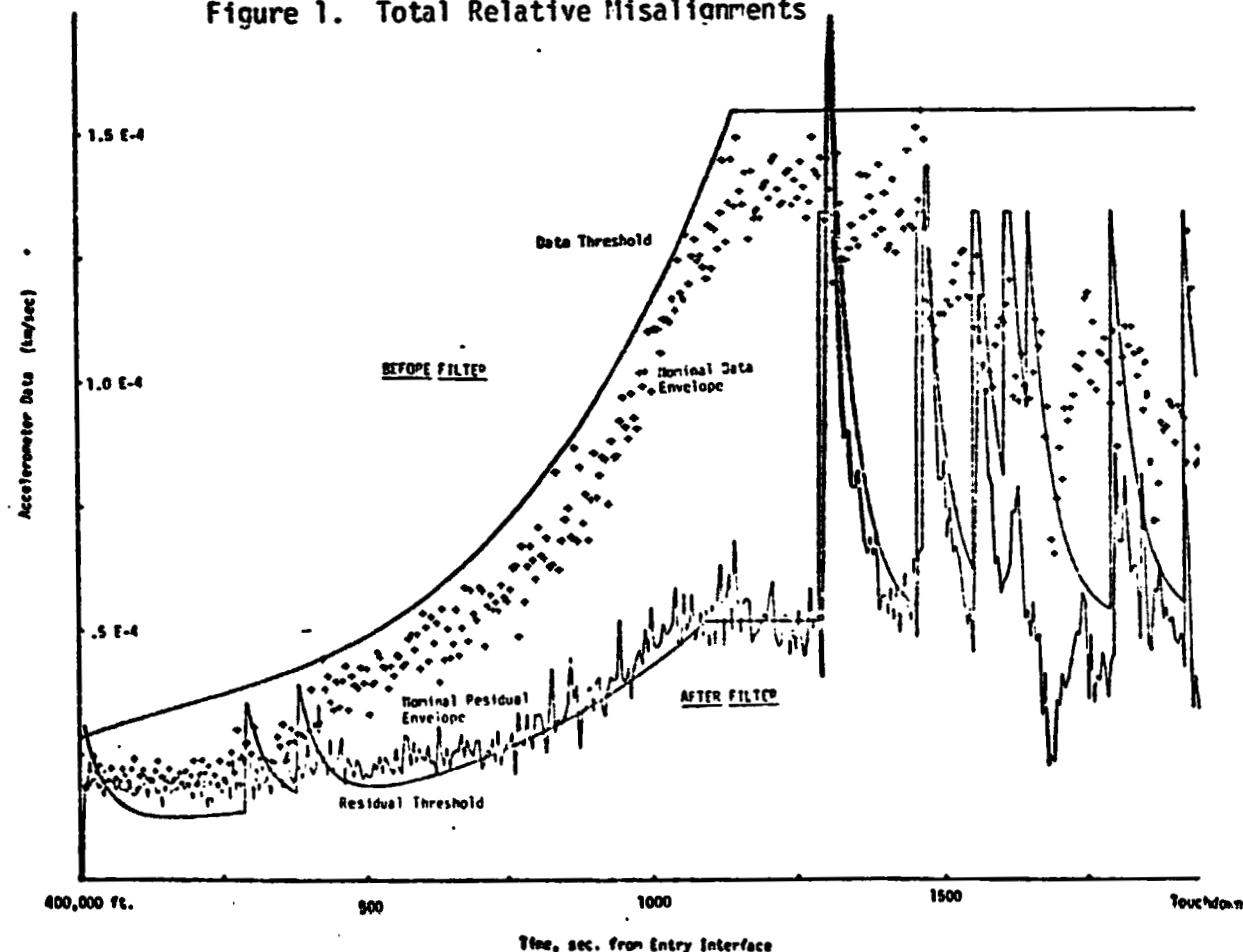


Figure 2. Incremental ΔV Differences

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The accelerometer threshold is a 3rd order polynomial which latches to a constant level at $t=1145$ sec. Before 1145, the threshold is specified by the following coefficients:

$$\begin{aligned}TACCL_0 &= 2.83 & E-5 \\TACCL_1 &= 4.3503 & E-8 \\TACCL_2 &= -5.3665 & E-11 \\TACCL_3 &= 9.7743 & E-14\end{aligned}$$

3.4 Log Likelihood Ratio Constants

The failure thresholds on the residuals after filtering are also plotted in Figures 1 and 2, together with envelopes of 100 Monte Carlo cycle nominal residuals. These thresholds are calculated from the base failure thresholds as described in Reference 1 using the following constants:

Attitude Transient Percentage

$$P_{NB, GYRO} = .15$$

$$P_{NB, ACCL} = .80$$

Attitude Transient Detect Level

$$\Delta_{GIM} = .226 \text{ radians}$$

Residual Standard Deviation

$$\sigma_{GYRO} = 2.4E-4 \text{ rad}$$

$$\sigma_{ACCL} = 1.2E-5 \text{ Km/sec}$$

Mean False Alarm Rate

$$\text{ALPHA} = \Delta t/T = 5/5000 = 10^{-3}$$

Where $T = 5000$ sec., mean time between false alarms

3.5 Skew Matrix

The ideal skewed transformation from IMU #1 to IMU #2 stable platform coordinate frames is given by:

$$T_{12} = \begin{bmatrix} -.5000000000 & .8090169944 & -.3090169944 \\ -.8090169944 & -.3090169944 & .5000000000 \\ .3090169944 & .5000000000 & .8090169944 \end{bmatrix}$$

3.6 IMU Platform to Nav Base Euler Matrix

The Kharfott IMU stable platform to navigation base transformation matrix is given by:

$$\begin{bmatrix} C\psi C\theta & C\psi S\theta & -S\psi \\ -C\phi S\theta + S\phi S\psi C\theta & C\phi C\theta + S\phi S\psi S\theta & S\phi C\psi \\ S\phi S\theta + C\phi S\psi C\theta & -S\phi C\theta + C\phi S\psi S\theta & C\phi C\psi \end{bmatrix}$$

where S=sine, C=cosine, ϕ , ψ , θ are the X, Y, Z gimbal angles, respectively.

3.7 IMU Entry Error Model

	Engineering Values	Program Values
ACCELEROMETER ERRORS (1σ) per axis		
bias	50 ug	.490333369-006 Km sec ²
scale factor	100 PPM	.0001
input axis misalignment	15 arc sec	.727220522-004 rad.
quantization	1×10^{-5} km/sec	1×10^{-5} Km/sec
GYRO ERRORS (1σ) per axis		
bias drift	0.035 deg/hr	.169684788-006 rad sec
g-sensitive drift-input axis	0.025 deg/hr/g	.123592917-004 (rad/sec) (Km/sec ²)
g-sensitive drift-spin axis	0.025 deg/hr/g	.123592917-004 (rad/sec) (Km/sec ²)
g^2 -sensitive drift-input/spin axis	0.025 deg/hr/g ²	.125826815-002 (rad/sec) (Km/sec ²) ²
scale factor	200 PPM	.0002
mounting alignment	60 arc sec	.290888209-003 rad
IMU ERRORS (1σ)		
IMU to nav. base	42.4 arc sec	.2056890249-003 rad
gimbal non-orthogonality	50 arc sec	.2424068405-003 rad
resolver bias term	0.	0
resolver sinusoidal term	30 arc sec	.1454441043-003 rad
resolver multiplicative speed	2	2
gimbal quantization	20 arc sec	.9696273622-004 rad
INITIAL ALIGNMENT ERRORS (1σ)		
each axis	132 arc sec	.6399540589-003 rad

4.0 RESULTS

Detection and isolation sensitivities of the 2-IMU SPRT algorithm were tested on failures in gyro drift, accelerometer bias, and accelerometer scale factor, introduced into IMU #1 at $t=0$ (400,000 ft). Failure levels were selected to correspond with the cases tested in Reference 2 so that performance of the SPRT and data tracking test could be compared under similar conditions. Failures in the following orientations were examined:

Single axis: X, Y, and Z axes

Dual axis: -45° and $+45^\circ$ in XY plane

Finally, for the sake of completeness, SPRT performance in the presence of no failure is summarized.

Each failure case is summarized in a six column table. The first column is the Monte Carlo cycle number. The second is the time (sec. from entry interface) of the first detection; this number will be equal to zero if there has been no detection during the cycle. The third column is the type of detection, ACCL or GYRO; this field will be blank if there has been no detection. Columns 4 and 5 are the same as columns 2 and 3, except that they pertain to the first isolation instead of the first detection. The sixth column is the IMU configuration control flag AFAIL, which is set after the first isolation. This number should be equal to 5 for all IMU #1 failures; it would be equal to 6 if the isolation logic indicated an IMU #2 failure.

4.1 Gyro Drift

Tables 1, 2, and 3 contain FDI performance summaries for $.5^\circ/\text{hr}$, $1^\circ/\text{hr}$, and $2^\circ/\text{hr}$ failures, respectively. The following observations are made on the basis of these data:

- .5°/hr detection was high but never 100%, ranging from 83% in the Z axis case to 97% in the -45° case
- 1°/hr isolation was 100% in only the +45° case, falling to 97% in the Y and Z cases, to 43% in the X case and 3% in the -45° case
- 2°/hr isolation was 100% in all but the -45° case. Average isolation times were sharply reduced from the 1°/hr cases. For example, Y axis average isolation time fell from 1515 sec. to 479 sec.

4.2 Accelerometer Bias

Tables 4, 5, and 6 contain FDI performance summaries for 1000 μ g, 1200 μ g, and 2000 μ g failures, respectively. The following observations are made on the basis of these data:

- 1000 μ g detection was high but never 100%, ranging from 87% in the -45° and Y cases to 93% in the X axis case
- 1200 μ g detection was 100% in all cases. 1200 μ g isolation ranged from 0% in the -45° and X cases to 50% in the +45° case
- 2000 μ g isolation was 100% in the +45°, Y, and Z cases, falling to 20% in the X case and 3% in the -45° case.

4.3 Accelerometer Scale Factor Error

Tables 7, 8, and 9 contain FDI performance summaries for 3000ppm, 5000ppm, and 8000ppm failures, respectively. The following observations are made on the basis of these data:

- The 100% detection level lies between 3000ppm and 5000ppm
- 5000ppm isolation was at best 90% in the X axis case

- 8000ppm isolation was 100% in the -45°, Y, and Z cases, falling to 97% in the +45° case, and to 63% in the X axis case.

4.4 Nominal

Table 10 contains the FDI performance summary in the nominal case. In a separate run (not included) the algorithm was tested during 100 nominal Monte Carlo cycles with no false detection or isolation.

5.0 CONCLUSIONS

The following conclusions are made on the basis of the data contained in section 4.0.

- For all cases run with the SPRT, there were no false detections in a 100 Monte Carlo cycle nominal case, and no incorrect isolations in the failure cases.
- Failure detection was sensitive, for all failure orientations, with the following 100% detection levels

gyro drift	$\approx .6^\circ/\text{hr}$
accelerometer bias	$\approx 1100\mu\text{g}$
accelerometer scale factor	$\approx 4000\text{ppm}$

- For the IMU pair tested (#1, #2), the best isolation geometry holds for the +45°, Y, and Z axis cases. Best geometry 100% isolation levels were found to be:

gyro drift	$1^\circ/\text{hr}$
accelerometer bias	$1400\mu\text{g}$
accelerometer scale factor	6000ppm

- -45° and X axis failures in gyro drift and accelerometer bias exhibited poor isolation geometry, since they were closest to the ambiguity line at -31.7° in the XY plane discussed in the

appendix of Reference 3. In the -45° case, 1°/hr isolation fell to 3%, and 2000 μ g isolation fell to 3%.

Reference 1 presented the following 100% levels for the tracking test:

Detection: .5°/hr, 800 μ g, 4000ppm

Isolation: 1°/hr, 1200 μ g, 5000ppm

Comparing these levels with those above for SPRT, the tracking test is slightly more sensitive than the SPRT. A comparison of response times shows the tracking test to be slightly faster in detection/isolation than the SPRT.

6.0 REFERENCES

1. T. M. Rich, "Performance Results of the Data Tracking Test for 2-IMU FDI", MDTSCO Working Paper No. E914-8A-026, 27 Feb. 1976.
2. T. M. Rich, "A Detailed Description of the Sequential Probability Ratio Test for 2-IMU FDI", MDTSCO Design Note No. D0410-007, 24 March 1976.
3. T. M. Rich, "Performance of the version 17.B Two IMU Single Axis FDI Logic in Detecting and Isolating Dual Axis Gyro Failures", MDTSCO Working Paper No. E914-8A-003, 18 Oct. 1974.

SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

-12-

CYCLE	1ST DETECTION	1ST ISOLATION
1	1835 GYRO	0
2	1835 GYRO	0
3	1835 GYRO	0
4	1835 GYRO	0
5	1835 GYRO	0
6	1835 GYRO	0
7	1835 GYRO	0
8	1835 GYRO	0
9	1835 GYRO	0
10	1835 GYRO	0
11	1835 GYRO	0
12	1835 GYRO	0
13	1835 GYRO	0
14	1835 GYRO	0
15	1835 GYRO	0
16	1835 GYRO	0
17	1835 GYRO	0
18	1835 GYRO	0
19	1835 GYRO	0
20	1835 GYRO	0
21	1835 GYRO	0
22	1835 GYRO	0
23	1835 GYRO	0
24	1835 GYRO	0
25	1835 GYRO	0
26	1835 GYRO	0
27	1835 GYRO	0
28	1835 GYRO	0
29	1835 GYRO	0
30	1835 GYRO	0
	46990	0

a) -45° in XY plane

SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

CYCLE	1ST DETECTION	1ST ISOLATION
1	1855 GYRO	0
2	1855 GYRO	0
3	1855 GYRO	0
4	1855 GYRO	0
5	1855 GYRO	0
6	1855 GYRO	0
7	1855 GYRO	0
8	1855 GYRO	0
9	1855 GYRO	0
10	1855 GYRO	0
11	1855 GYRO	0
12	1855 GYRO	0
13	1855 GYRO	0
14	1855 GYRO	0
15	1855 GYRO	0
16	1855 GYRO	0
17	1855 GYRO	0
18	1855 GYRO	0
19	1855 GYRO	0
20	1855 GYRO	0
21	1855 GYRO	0
22	1855 GYRO	0
23	1855 GYRO	0
24	1855 GYRO	0
25	1855 GYRO	0
26	1855 GYRO	0
27	1855 GYRO	0
28	1855 GYRO	0
29	1855 GYRO	0
30	1855 GYRO	0
	41575	0

b) X axis

SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

CYCLE	1ST DETECTION	1ST ISOLATION
1	1855 GYRO	0
2	0	0
3	1855 GYRO	0
4	1855 GYRO	0
5	1855 GYRO	0
6	1855 GYRO	0
7	1855 GYRO	0
8	1855 GYRO	0
9	0	0
10	1845 GYRO	0
11	1845 GYRO	0
12	1845 GYRO	0
13	0	0
14	1845 GYRO	0
15	1845 GYRO	0
16	0	0
17	1845 GYRO	0
18	1845 GYRO	0
19	0	0
20	1845 GYRO	0
21	1845 GYRO	0
22	1845 GYRO	0
23	1845 GYRO	0
24	1845 GYRO	0
25	1845 GYRO	0
26	1845 GYRO	0
27	1845 GYRO	0
28	1845 GYRO	0
29	1845 GYRO	0
30	1835 GYRO	0
	43245	14735

c) +45° in XY plane

SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

CYCLE	1ST DETECTION	1ST ISOLATION
1	1760 GYRO	0
2	1715 GYRO	0
3	1550 GYRO	0
4	1870 GYRO	0
5	1910 GYRO	0
6	1840 GYRO	0
7	4100 GYRO	1785 GYRO
8	1750 GYRO	0
9	1775 GYRO	0
10	1860 GYRO	0
11	1785 GYRO	0
12	1735 GYRO	0
13	0	0
14	1855 GYRO	0
15	1855 GYRO	0
16	1750 GYRO	0
17	1630 GYRO	0
18	1440 GYRO	0
19	1710 GYRO	0
20	1720 GYRO	0
21	1725 GYRO	0
22	1660 GYRO	0
23	1780 GYRO	0
24	0	0
25	1730 GYRO	0
26	1055 GYRO	0
27	4100 GYRO	0
28	1780 GYRO	0
29	1795 GYRO	0
30	1775 GYRO	0
	46645	1785

d) Y axis

SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

CYCLE	1ST DETECTION	1ST ISOLATION
1	1745 GYRO	0
2	1775 GYRO	0
3	1715 GYRO	1715 GYRO
4	1455 GYRO	1650 GYRO
5	1780 GYRO	0
6	1870 GYRO	0
7	1395 GYRO	0
8	1865 GYRO	1910 GYRO
9	900 GYRO	0
10	0	0
11	1775 GYRO	1875 GYRO
12	1455 GYRO	0
13	0	0
14	1735 GYRO	1660 GYRO
15	1735 GYRO	1795 GYRO
16	1575 GYRO	1795 GYRO
17	1905 GYRU	0
18	0	0
19	1265 GYRO	1670 GYRO
20	1770 GYRO	1710 GYRO
21	1690 GYRO	1710 GYRO
22	0	0
23	0	0
24	1215 GYRO	1655 GYRO
25	1675 GYRO	1915 GYRO
26	1550 GYRO	1675 GYRO
27	1670 GYRO	1675 GYRO
28	1790 GYRO	0
29	1860 GYRO	0
30	1860 GYRO	0
	41335	20430

e) Z axis

Table 1. .5 °/hr Gyro Drift, IMU #1

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SPOT DETECTION/ISOLATION PERFORMANCE SUMMARY

-13-

SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

CYCLE	1ST DETECTION	1ST ISOLATION
665	GYRO	
319	GYRO	
510	GYRO	
525	GYRO	
565	GYRO	
615	GYRO	
620	GYRO	
625	GYRO	
629	GYRO	
635	GYRO	
636	GYRO	
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933	GYRO	
934	GYRO	
935	GYRO	
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968	GYRO	
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977	GYRO	
978	GYRO	
979	GYRO	
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981	GYRO	
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984	GYRO	
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988	GYRO	
989	GYRO	
990	GYRO	
991	GYRO	
992	GYRO	
993	GYRO	
994	GYRO	
995	GYRO	
996	GYRO	
997	GYRO	
998	GYRO	
999	GYRO	
1000	GYRO	

a) -45° in XY plane

CYCLE	1ST DETECTION	1ST ISOLATION	
1140	GYRO	1940	GYRO
1150	GYRO	1870	GYRO
1155	GYRO	1865	GYRO
1165	GYRO	1865	GYRO
1170	GYRO	1775	GYRO
1175	GYRO	1720	GYRO
1180	GYRO	1870	GYRO
1185	GYRO	1900	GYRO
1190	GYRO	1840	GYRO
1195	GYRO	1810	GYRO
1200	GYRO	1840	GYRO
1205	GYRO	1840	GYRO
1210	GYRO	1840	GYRO
1215	GYRO	1840	GYRO
1220	GYRO	1840	GYRO
1225	GYRO	1840	GYRO
1230	GYRO	1840	GYRO
1235	GYRO	1840	GYRO
1240	GYRO	1840	GYRO
1245	GYRO	1840	GYRO
1250	GYRO	1840	GYRO
1255	GYRO	1840	GYRO
1260	GYRO	1840	GYRO
1265	GYRO	1840	GYRO
1270	GYRO	1840	GYRO
1275	GYRO	1840	GYRO
1280	GYRO	1840	GYRO
1285	GYRO	1840	GYRO
1290	GYRO	1840	GYRO
1295	GYRO	1840	GYRO
1300	GYRO	1840	GYRO
1305	GYRO	1840	GYRO
1310	GYRO	1840	GYRO
1315	GYRO	1840	GYRO
1320	GYRO	1840	GYRO
1325	GYRO	1840	GYRO
1330	GYRO	1840	GYRO
1335	GYRO	1840	GYRO
23295		23555	

b) x axis

SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

CYCLE	1ST DETECTION	1ST ISOLATION
1	1615	GYRO
2	1175	GYRO
3	1045	GYRO
4	1705	GYRO
5	1385	GYRO
6	1255	GYRO
7	375	GYRO
8	635	GYRO
9	545	GYRO
10	1450	GYRO
11	57	GYRO
12	443	GYRO
13	1245	GYRO
14	646	GYRO
15	626	GYRO
16	625	GYRO
17	515	GYRO
18	895	GYRO
19	657	GYRO
20	527	GYRO
21	377	GYRO
22	626	GYRO
23	495	GYRO
24	645	GYRO
25	1460	GYRO
26	295	GYRO
27	1135	GYRO
28	925	GYRO
29	1145	GYRO
30		
	2433U	42015

c) + 45° in XY plane

SPAT DETECTION/ISOLATION PERFORMANCE SUMMARY

d) Y axis

SPOT DETECTION/ISOLATION PERFORMANCE SUMMARY

CYCLE	1ST DETECTION	1ST ISOLATION
695	GYRO	1100
325	GYRO	735
535	GYRO	585
335	GYRO	385
355	GYRO	75
395	GYRO	1275
535	GYRO	1455
401055	GYRO	1355
46655	LYNO	1710
675	GYRO	671
285	GYRO	1720
67L	GYRO	715
1C60	GYRO	1620
345	GYRG	1625
93L	GYRO	1195
1150	LYNO	1780
545	GYRO	1780
365	GYRO	1700
650	GYRO	1785
770	LYNO	1735
595	GYRO	1640
31L	GYHO	1720
515	GYHO	1720
65U	GYRO	1735
33U	GYRO	1160
780	GYHO	1075
67D	GYRO	1260
44C	GYNO	1735

Table 2. 1 °/hr Gyro Drift, IMU #1

ORIGINAL PAGE IS
OF POOR QUALITY

e) Z axis

SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

-14-

SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

CYCLE	1ST DETECTION	1ST ISOLATION
190	GYRO	GYRO
180	GYRO	GYRO
210	GYRO	GYRO
175	GYRO	GYRO
160	GYRO	GYRO
190	GYRO	GYRO
195	GYRO	GYRO
250	GYRO	1730 GYRO
155	GYRO	GYRO
205	GYRO	1775 GYRO
200	GYRO	1915 GYRO
235	GYRO	GYRO
240	GYRO	GYRO
260	GYRO	1785 GYRO
260	GYRO	1860 GYRO
250	GYRO	1795 GYRO
190	GYRO	1910 GYRO
205	GYRO	1875 GYRO
275	GYRO	1845 GYRO
170	GYRO	1915 GYRO
185	GYRO	1920 GYRO
205	GYRO	1760 GYRO
30		
6500		22080

a) -45° in XY plane

CYCLE	1ST DETECTION	1ST ISOLATION
1	GYRO	GYRO
2	GYRO	GYRO
3	GYRO	GYRO
4	GYRO	GYRO
5	GYRO	GYRO
6	GYRO	GYRO
7	GYRO	GYRO
8	GYRO	GYRO
9	GYRO	GYRO
10	GYRO	GYRO
11	GYRO	GYRO
12	GYRO	GYRO
13	GYRO	GYRO
14	GYRO	GYRO
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16	GYRO	GYRO
17	GYRO	GYRO
18	GYRO	GYRO
19	GYRO	GYRO
20	GYRO	GYRO
21	GYRO	GYRO
22	GYRO	GYRO
23	GYRO	GYRO
24	GYRO	GYRO
25	GYRO	GYRO
26	GYRO	GYRO
27	GYRO	GYRO
28	GYRO	GYRO
29	GYRO	GYRO
30	GYRO	GYRO
6300		35020

b) X axis

SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

CYCLE	1ST DETECTION	1ST ISOLATION
1	GYRO	GYRO
2	GYRO	GYRO
3	GYRO	GYRO
4	GYRO	GYRO
5	GYRO	GYRO
6	GYRO	GYRO
7	GYRO	GYRO
8	GYRO	GYRO
9	GYRO	GYRO
10	GYRO	GYRO
11	GYRO	GYRO
12	GYRO	GYRO
13	GYRO	GYRO
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23	GYRO	GYRO
24	GYRO	GYRO
25	GYRO	GYRO
26	GYRO	GYRO
27	GYRO	GYRO
28	GYRO	GYRO
29	GYRO	GYRO
30	GYRO	GYRO
7335		11540

c) +45° in XY plane

SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

CYCLE	1ST DETECTION	1ST ISOLATION
1	GYRO	GYRO
2	GYRO	GYRO
3	GYRO	GYRO
4	GYRO	GYRO
5	GYRO	GYRO
6	GYRO	GYRO
7	GYRO	GYRO
8	GYRO	GYRO
9	GYRO	GYRO
10	GYRO	GYRO
11	GYRO	GYRO
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13	GYRO	GYRO
14	GYRO	GYRO
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16	GYRO	GYRO
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18	GYRO	GYRO
19	GYRO	GYRO
20	GYRO	GYRO
21	GYRO	GYRO
22	GYRO	GYRO
23	GYRO	GYRO
24	GYRO	GYRO
25	GYRO	GYRO
26	GYRO	GYRO
27	GYRO	GYRO
28	GYRO	GYRO
29	GYRO	GYRO
30	GYRO	GYRO
6465		14380

d) Y axis

SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

CYCLE	1ST DETECTION	1ST ISOLATION
1	GYRO	GYRO
2	GYRO	GYRO
3	GYRO	GYRO
4	GYRO	GYRO
5	GYRO	GYRO
6	GYRO	GYRO
7	GYRO	GYRO
8	GYRO	GYRO
9	GYRO	GYRO
10	GYRO	GYRO
11	GYRO	GYRO
12	GYRO	GYRO
13	GYRO	GYRO
14	GYRO	GYRO
15	GYRO	GYRO
16	GYRO	GYRO
17	GYRO	GYRO
18	GYRO	GYRO
19	GYRO	GYRO
20	GYRO	GYRO
21	GYRO	GYRO
22	GYRO	GYRO
23	GYRO	GYRO
24	GYRO	GYRO
25	GYRO	GYRO
26	GYRO	GYRO
27	GYRO	GYRO
28	GYRO	GYRO
29	GYRO	GYRO
30	GYRO	GYRO
6375		14030

e) Z axis

Table 3. 2 °/hr Gyro Drift, IMU #1

ORIGINAL PAGE IS
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SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

-15-

SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

CYCLE	1ST DETECTION	1ST ISOLATION
30	ACCL	
25	ACCL	
60	ACCL	
120	ACCL	
180	ACCL	
90	ACCL	
150	ACCL	
250	ACCL	
80	ACCL	
210	ACCL	
21	ACCL	
125	ACCL	
25	ACCL	
30	ACCL	
41	ACCL	
25	ACCL	
25	ACCL	
35	ACCL	
25	ACCL	
900		

a) -45° in XY plane

CYCLE	1ST DETECTION	1ST ISOLATION
30	ACCL	
25	ACCL	
60	ACCL	
120	ACCL	
180	ACCL	
90	ACCL	
150	ACCL	
250	ACCL	
80	ACCL	
210	ACCL	
21	ACCL	
125	ACCL	
25	ACCL	
30	ACCL	
41	ACCL	
25	ACCL	
25	ACCL	
35	ACCL	
25	ACCL	
720		

b) X axis

SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

CYCLE	1ST DETECTION	1ST ISOLATION
60	ACCL	
25	ACCL	
60	ACCL	
120	ACCL	
180	ACCL	
90	ACCL	
150	ACCL	
250	ACCL	
80	ACCL	
210	ACCL	
21	ACCL	
125	ACCL	
25	ACCL	
30	ACCL	
41	ACCL	
25	ACCL	
25	ACCL	
35	ACCL	
25	ACCL	
1365		ACCL
53		

c) +45° in XY plane

CYCLE	1ST DETECTION	1ST ISOLATION
25	ACCL	
125	ACCL	
60	ACCL	
120	ACCL	
180	ACCL	
90	ACCL	
150	ACCL	
250	ACCL	
80	ACCL	
210	ACCL	
21	ACCL	
125	ACCL	
25	ACCL	
30	ACCL	
41	ACCL	
25	ACCL	
25	ACCL	
35	ACCL	
25	ACCL	
15	ACCL	
630		ACCL

d) Y axis

CYCLE	1ST DETECTION	1ST ISOLATION
20	ACCL	
35	ACCL	
15	ACCL	
20	ACCL	
15	ACCL	
25	ACCL	
15	ACCL	
25	ACCL	
15	ACCL	
25	ACCL	
15	ACCL	
25	ACCL	
15	ACCL	
25	ACCL	
15	ACCL	
35	ACCL	
15	ACCL	
15	ACCL	
15	ACCL	
31	ACCL	
630		ACCL

e) Z axis

Table 4. 1000 µg Accelerometer Bias, IMU #1

ORIGINAL PAGE IS
OF POOR QUALITY

SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

CYCLE	1ST DETECTION	1ST ISOLATION
1	ACCL	
2	ACCL	
3	ACCL	
4	ACCL	
5	ACCL	
6	ACCL	
7	ACCL	
8	ACCL	
9	ACCL	
10	ACCL	
11	ACCL	
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463	ACCL	

SPOT DETECTION/ISOLATION PERFORMANCE SUMMARY

-17-

SPOT DETECTION/ISOLATION PERFORMANCE SUMMARY

CYCLE	1ST DETECTION	1ST ISOLATION
1	ACCL	
2	ACCL	
3	ACCL	
4	ACCL	
5	ACCL	
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SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

-18-

SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

CYCLE	1ST DETECTION	1ST ISOLATION
1274	ACCL	
821	ACCL	
70	ACCL	1135
96	ACCL	1135
1135	ACCL	
1176	ACCL	
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1197	ACCL	1135
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SPIRIT DETECTION/ISOLATION PERFORMANCE SUMMARY

- 19 -

CYCLE	1ST DETECTION	1ST ISOLATION
517	ACCL	7
378	ACLL	8
57	ACLL	9
69	ACCL	1045 ACCL
65	ACCL	105 ACCL
66	ACLL	79 ACCL
655	ACCL	915 ACCL
77	ACLL	1035 ACCL
275	ACCL	1265 ACCL
695	ACCL	941 ACCL
955	ACCL	961 ACCL
38	ACCL	993 ACCL
665	ACCL	993 ACCL
49	ACLL	107 ACCL
67	ACCL	79 ACCL
67	ACCL	215 ACCL
465	ACLL	215 ACCL
87	ACLL	215 ACCL
57	ACCL	215 ACCL
38	ACCL	415 ACCL
69	ACCL	415 ACCL
65	ACCL	415 ACCL
51	ACCL	415 ACCL
39	ACCL	415 ACCL
47	ACCL	415 ACCL
38	ACCL	69 ACCL
27	ACCL	83 ACCL
276	ACCL	83 ACCL

1431

3248

a) -45° in XY plane

•PRS DETECTION/ISULATION PERFORMANCE: SUMMARY

1492

b) x axis

~~SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY~~

CYCLE	1ST DETECTION		1ST ISGLATION
5	ACCL	95.5	ACCL
695	ACCL	95	ACCL
88	ACCL	95	ACCL
524	ACCL	95	ACCL
51	ACCL	95	ACCL
67	ACCL	95	ACCL
57	ACCL	95	ACCL
55	ACCL	95	ACCL
665	ACCL	95	ACCL
666	ACCL	95	ACCL
77	ACCL	95	ACCL
695	ACCL	175	ACCL
98	ACCL	175	ACCL
81	ACCL	175	ACCL
725	ACCL	175	ACCL
79	ACCL	175	ACCL
435	ACCL	175	ACCL
62	ACCL	175	ACCL
81	ACCL	175	ACCL
67	ACCL	175	ACCL
515	ACCL	175	ACCL
485	ACCL	175	ACCL
72	ACCL	175	ACCL
625	ACCL	175	ACCL
815	ACCL	175	ACCL
57	ACCL	175	ACCL

4607

2

c) $+45^\circ$ in XY plane

SART DETECTION/ISOLATION PERFORMANCE SUMMARY

d) Y axis

Y-axes

SFR T DETECTION/ISOLATION PERFORMANCE SUMMARY

e) Z axis

Table 8. 5000 ppm Accelerometer Scale

Factor Error, IMU #1

ORIGINAL PAGE IS
OF POOR QUALITY

SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

-20-

CYCLE	1ST DETECTION	1ST ISOLATION
1	ACCL	ACCL
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3	ACCL	ACCL
4	ACCL	ACCL
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a) -45° in XY plane

SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

CYCLE	1ST DETECTION	1ST ISOLATION
1	ACCL	ACCL
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b) X axis

SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

CYCLE	1ST DETECTION	1ST ISOLATION
1	ACCL	ACCL
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c) +45° in XY plane

SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

CYCLE	1ST DETECTION	1ST ISOLATION
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26	ACCL	ACCL
27	ACCL	ACCL
28	ACCL	ACCL
29	ACCL	ACCL

d) Y axis

SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

CYCLE	1ST DETECTION	1ST ISOLATION
1	ACCL	ACCL
2	ACCL	ACCL
3	ACCL	ACCL
4	ACCL	ACCL
5	ACCL	ACCL
6	ACCL	ACCL
7	ACCL	ACCL
8	ACCL	ACCL
9	ACCL	ACCL
10	ACCL	ACCL
11	ACCL	ACCL
12	ACCL	ACCL
13	ACCL	ACCL
14	ACCL	ACCL
15	ACCL	ACCL
16	ACCL	ACCL
17	ACCL	ACCL
18	ACCL	ACCL
19	ACCL	ACCL
20	ACCL	ACCL
21	ACCL	ACCL
22	ACCL	ACCL
23	ACCL	ACCL
24	ACCL	ACCL
25	ACCL	ACCL
26	ACCL	ACCL
27	ACCL	ACCL
28	ACCL	ACCL
29	ACCL	ACCL

e) Z axis

Table 9. 8000 ppm Accelerometer Scale Factor Error, IMU #1

RECORDED BY
DATA ACQUISITION

SPRT DETECTION/ISOLATION PERFORMANCE SUMMARY

CYCLE	1ST-DETECTION	1ST-ISOLATION
1	0	0
2	0	0
3	00	00
4	00	00
5	00	00
6	00	00
7	00	00
8	00	00
9	00	00
10	00	00
11	00	00
12	00	00
13	00	00
14	00	00
15	00	00
16	00	00
17	00	00
18	00	00
19	00	00
20	00	00
21	00	00
22	00	00
23	00	00
24	00	00
25	00	00
26	00	00
27	00	00
28	00	00
29	00	00
30	00	00
	0	0

Table 10. Nominal IMU's #1 and #2